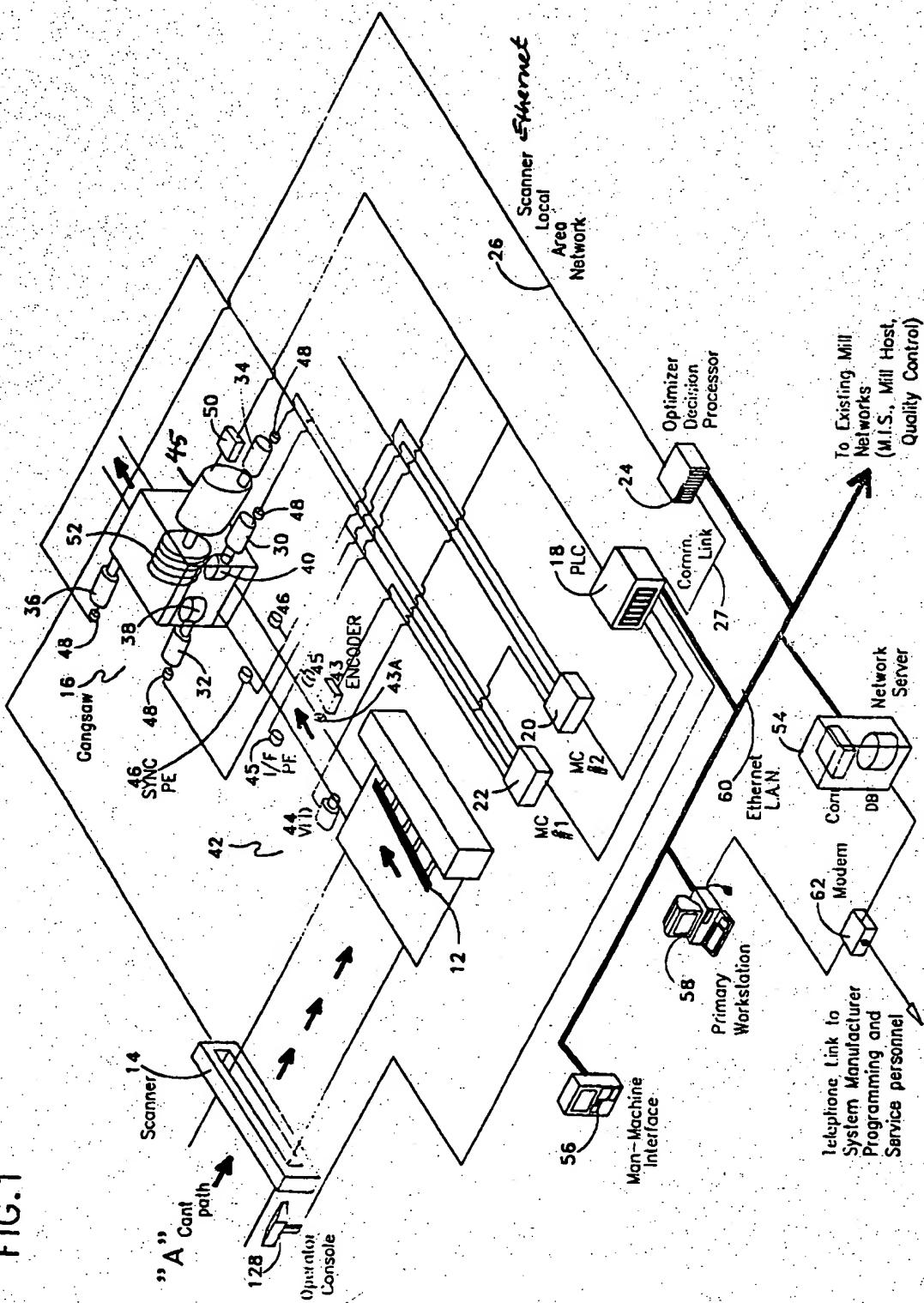


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FIG. 1



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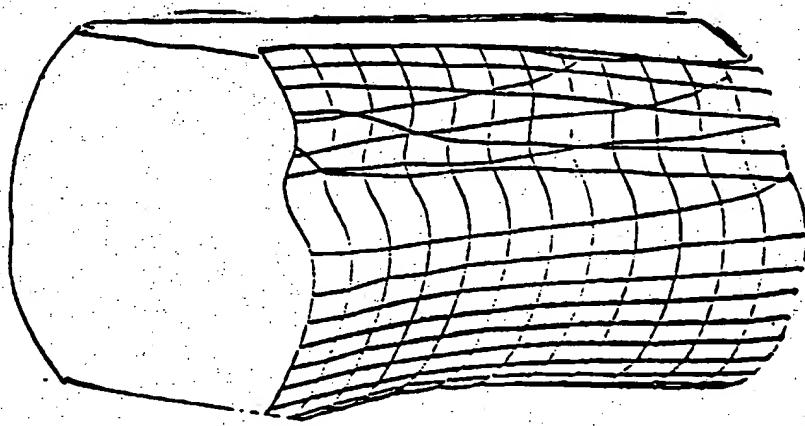
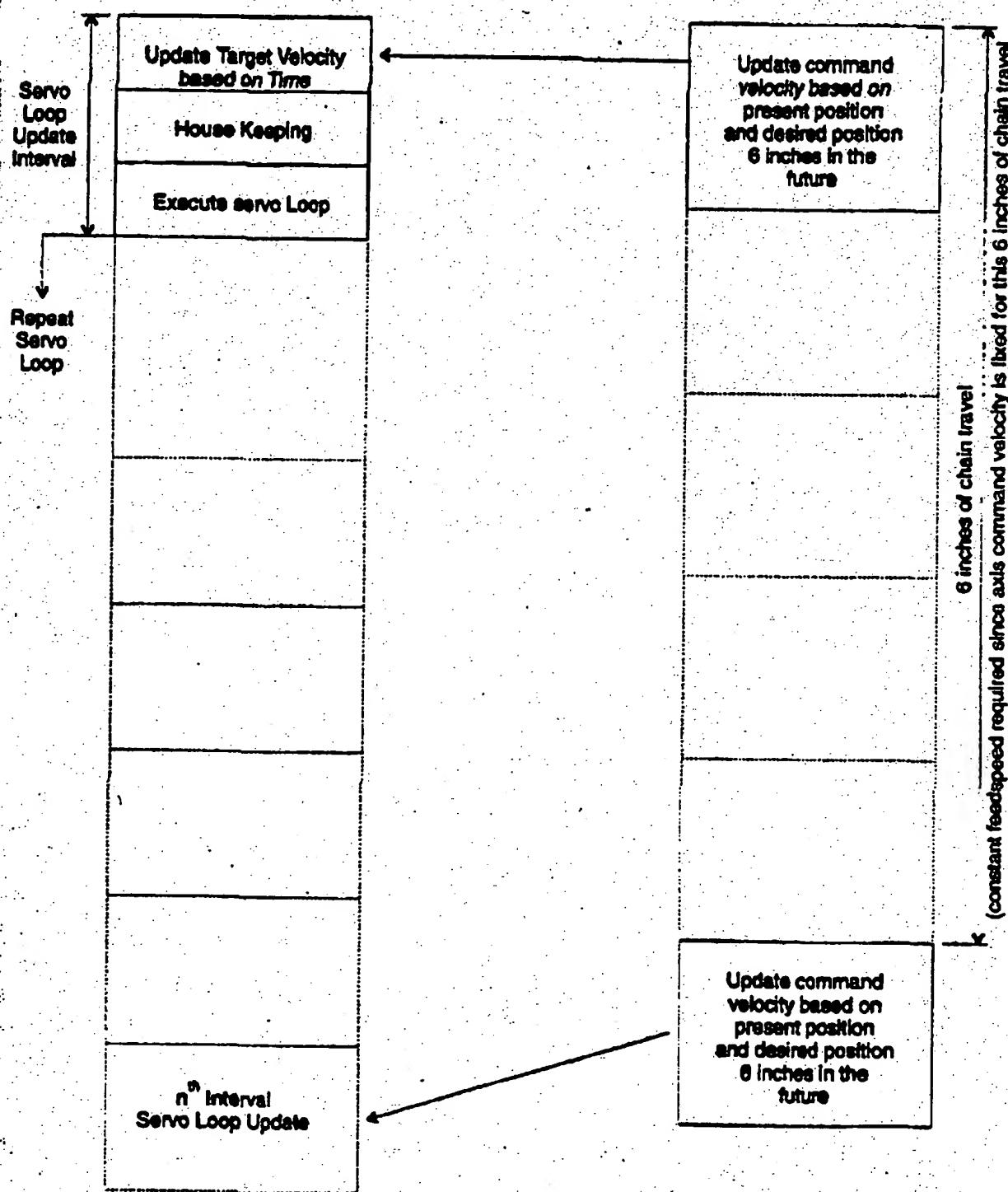


FIG. 1a

QB/Delta Module

PLC



NOTE: This drawing depicts functionality only.

This is not an exact representation of the task divisions within the motion controller.

FIG. 2

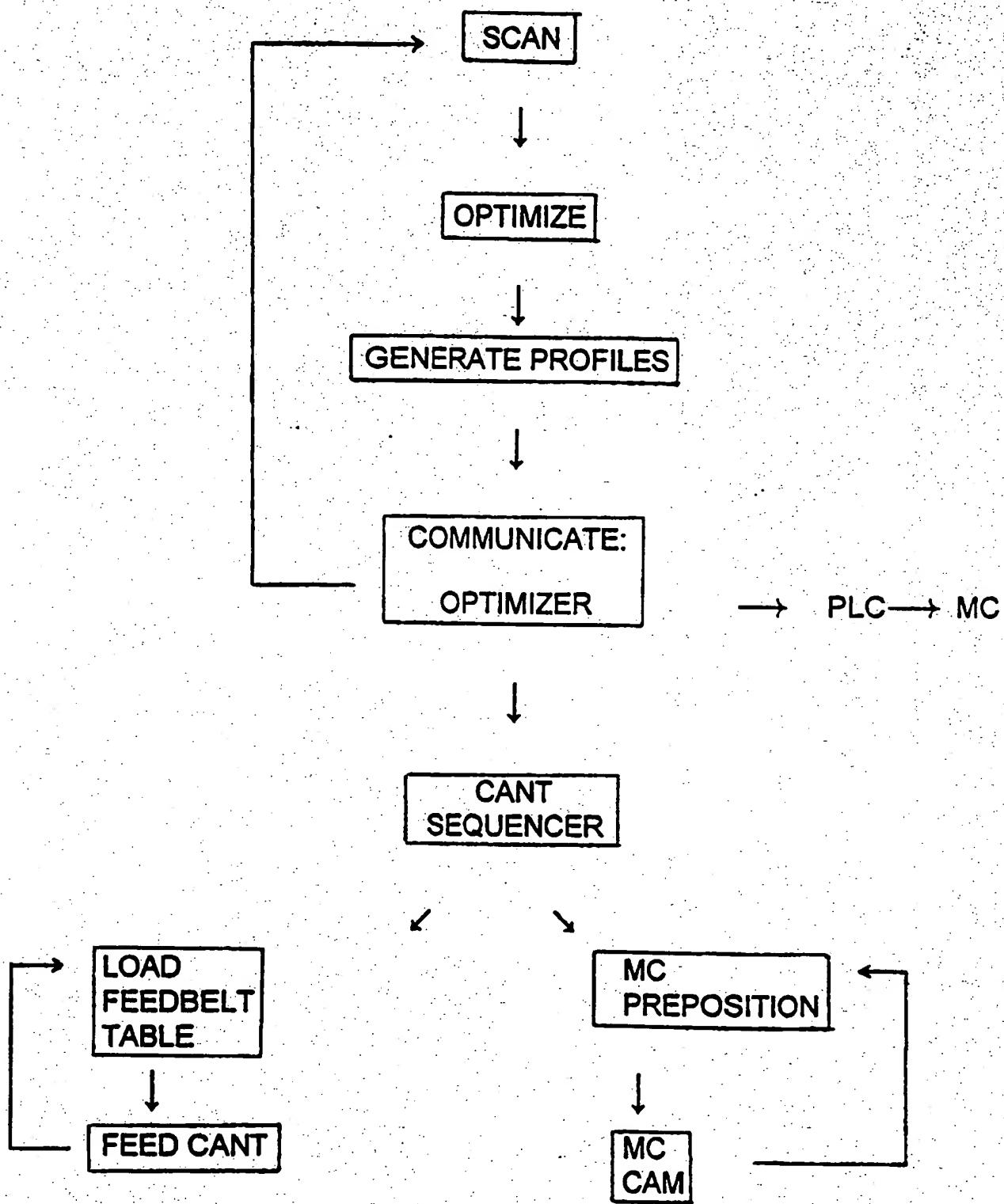
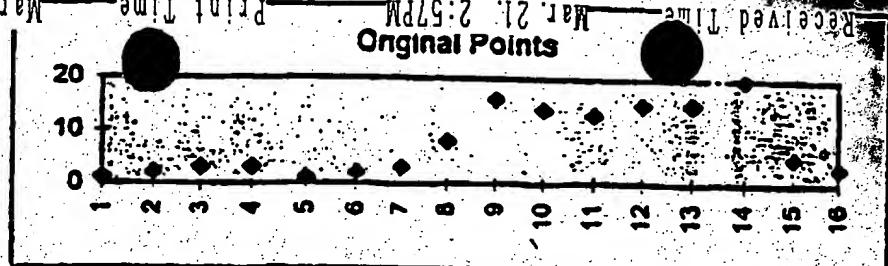


FIG. 3

FIG. 4a



1. Generate Polynomial

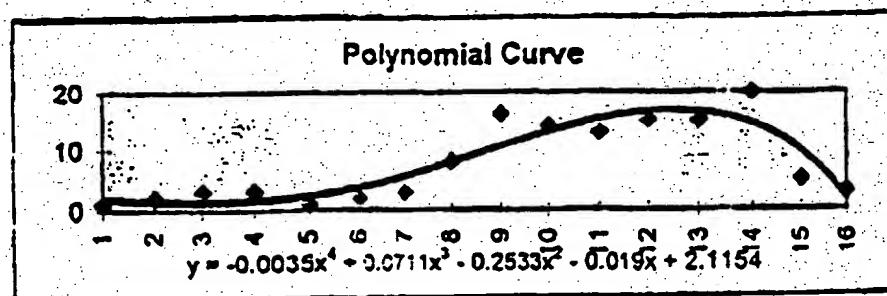


FIG. 4b

2. Calculate discrete points

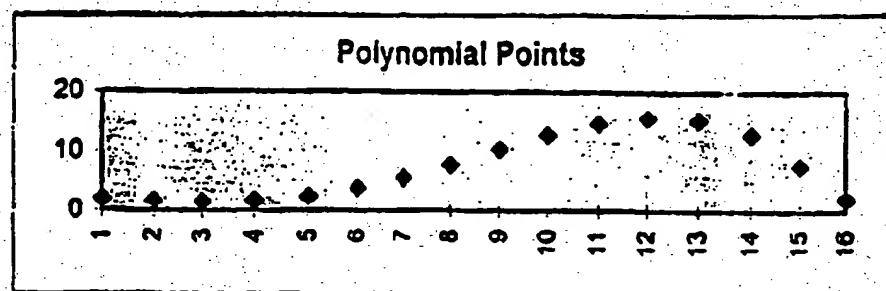


FIG. 4c

3. Apply machine constraints

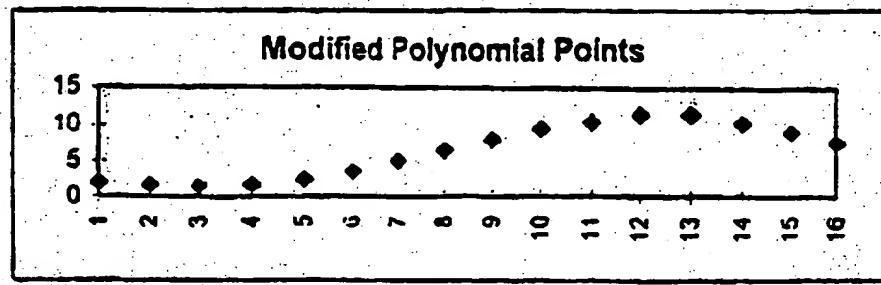


FIG 4d

4. Re-generate polynomial

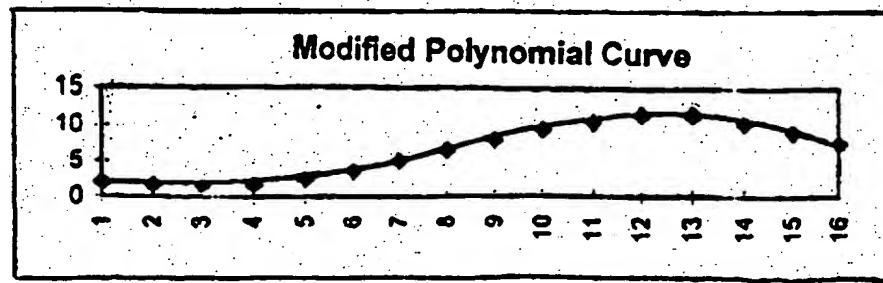
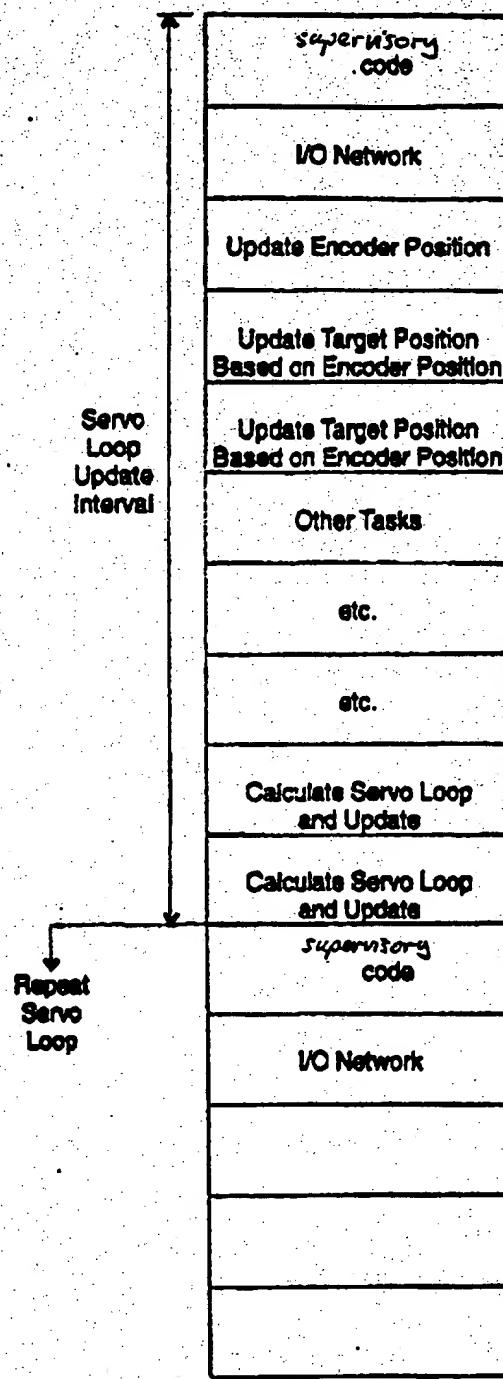


FIG. 4e

MC Motion Control



NOTE: This drawing depicts functionality only.

This is not an exact representation of the task divisions within the motion controller

FIG 5a

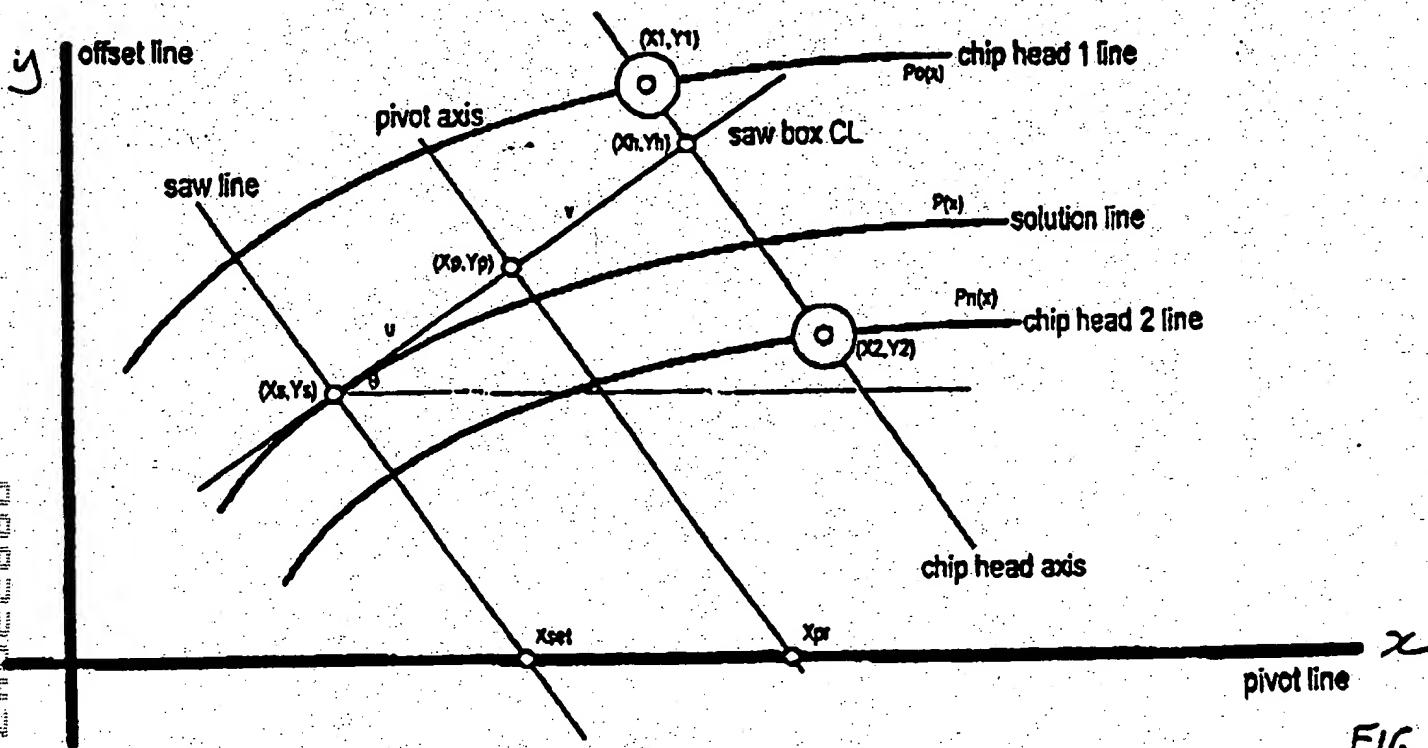


FIG. 5b

18/822947

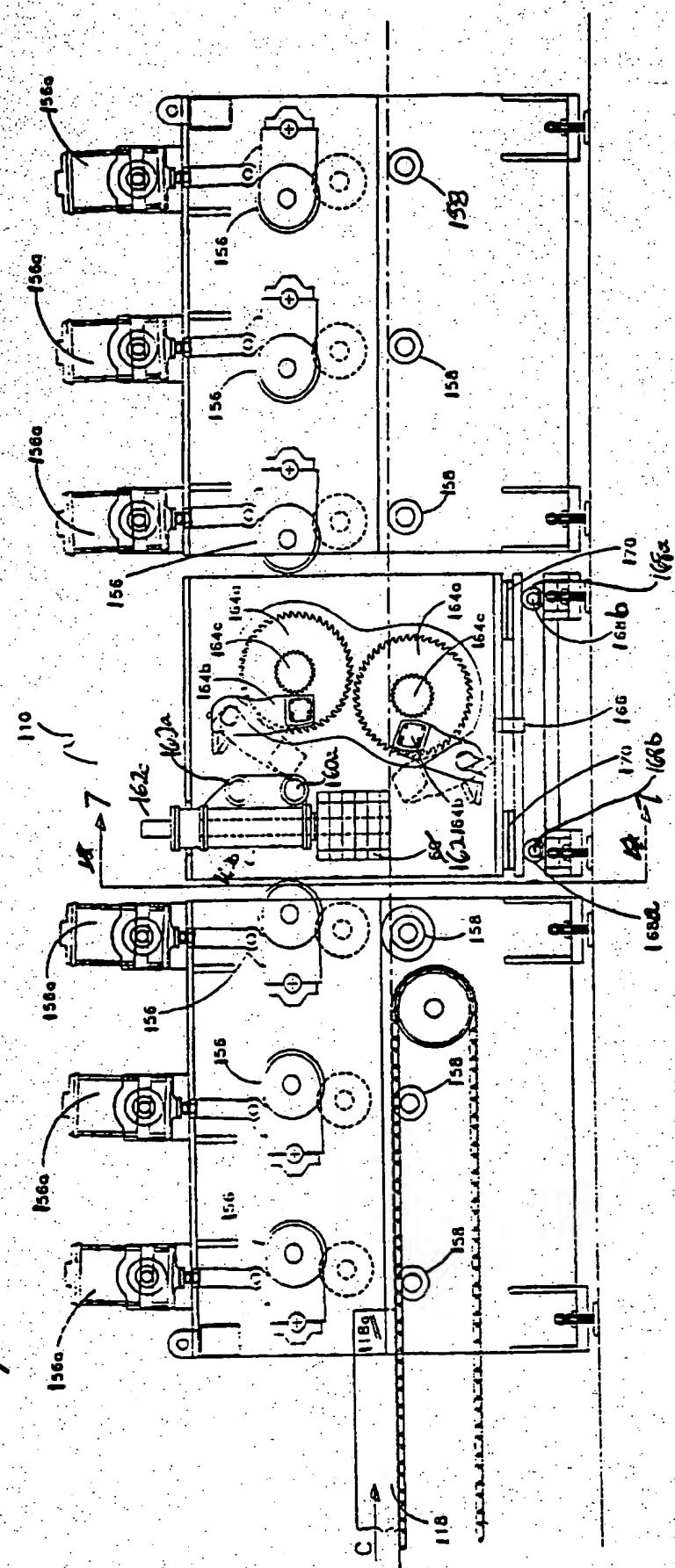
Received Time

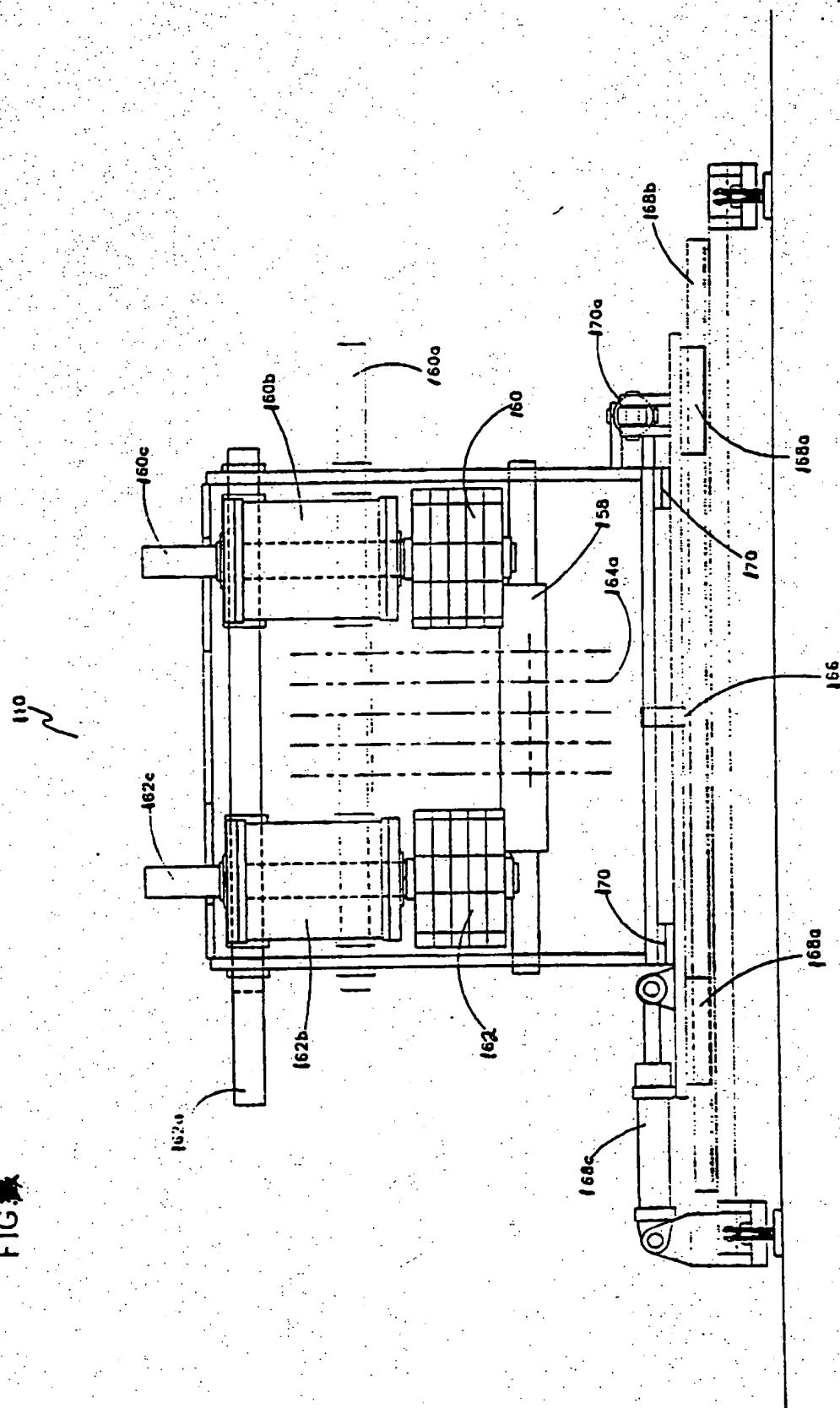
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Mar. 21, 3:26PM

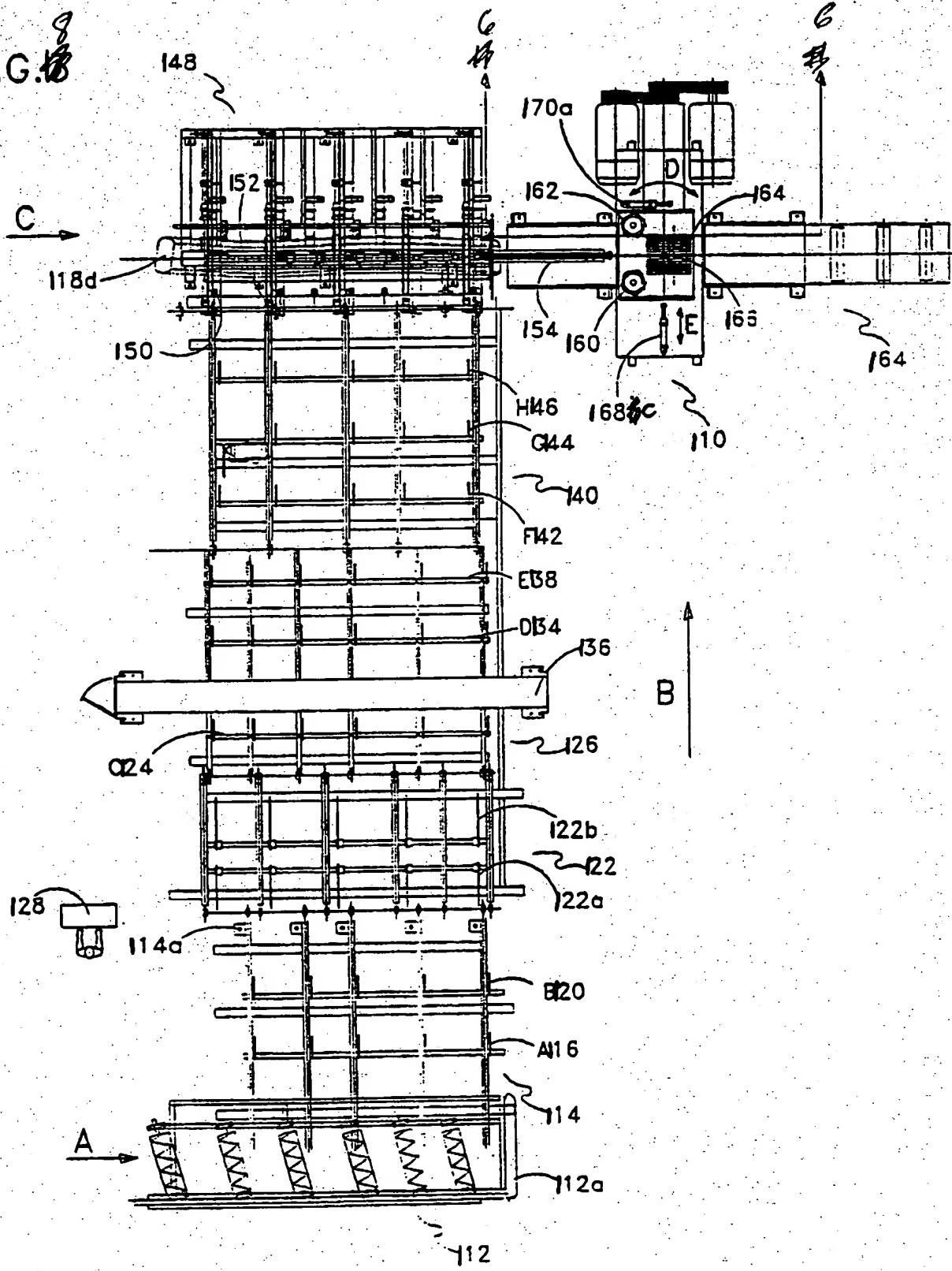
Mar. 21, 3:26PM

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FIG. 1A



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FIG. 8



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FIG. 9

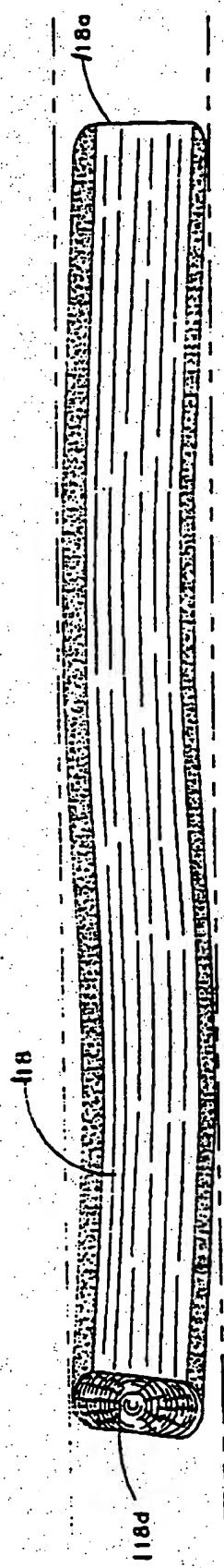


FIG. 9a

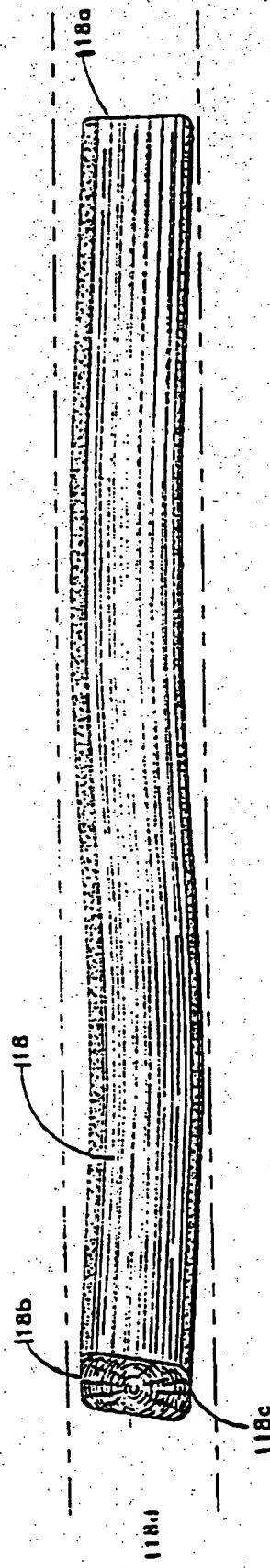


FIG. 10

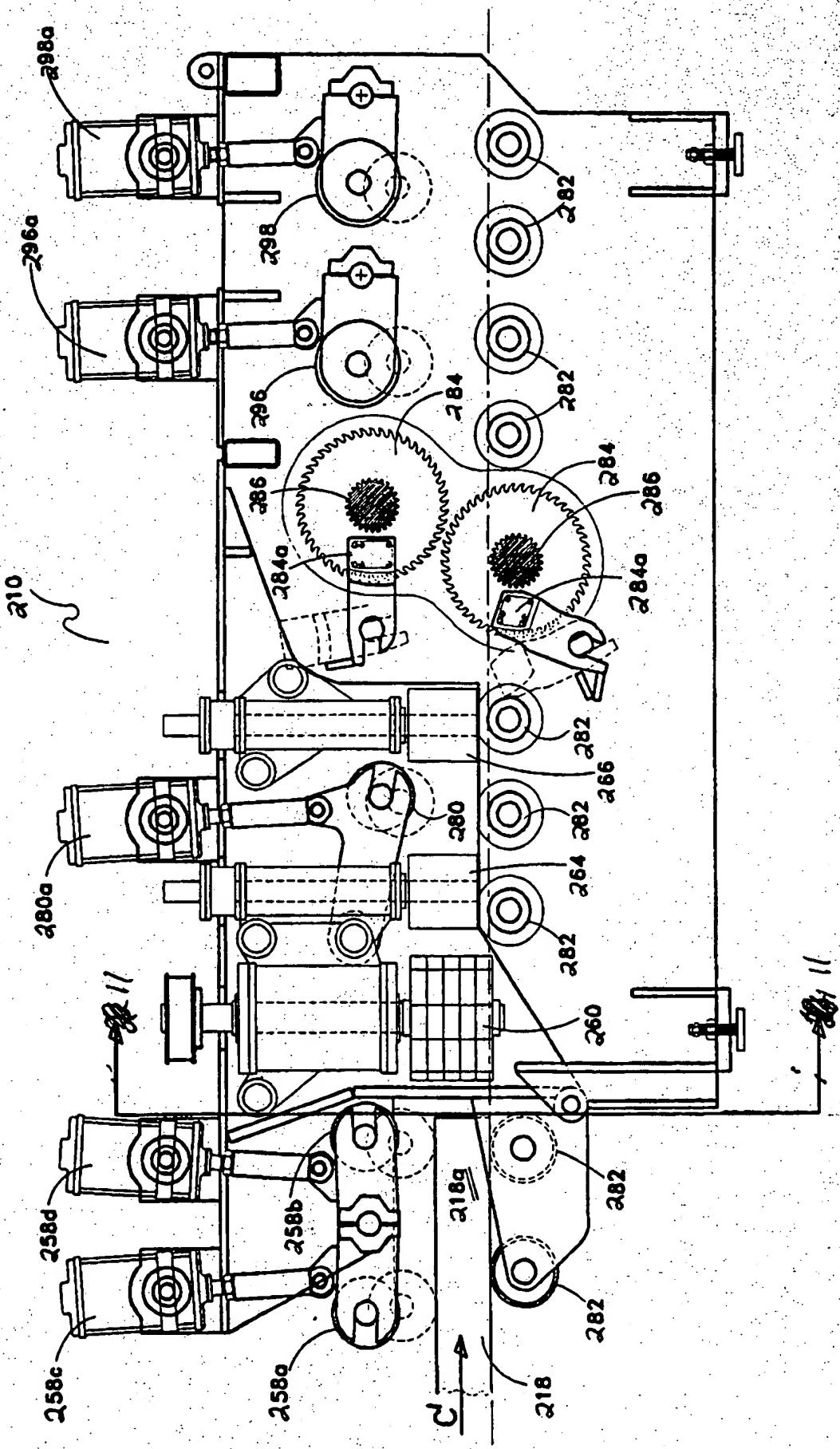


FIG. 21

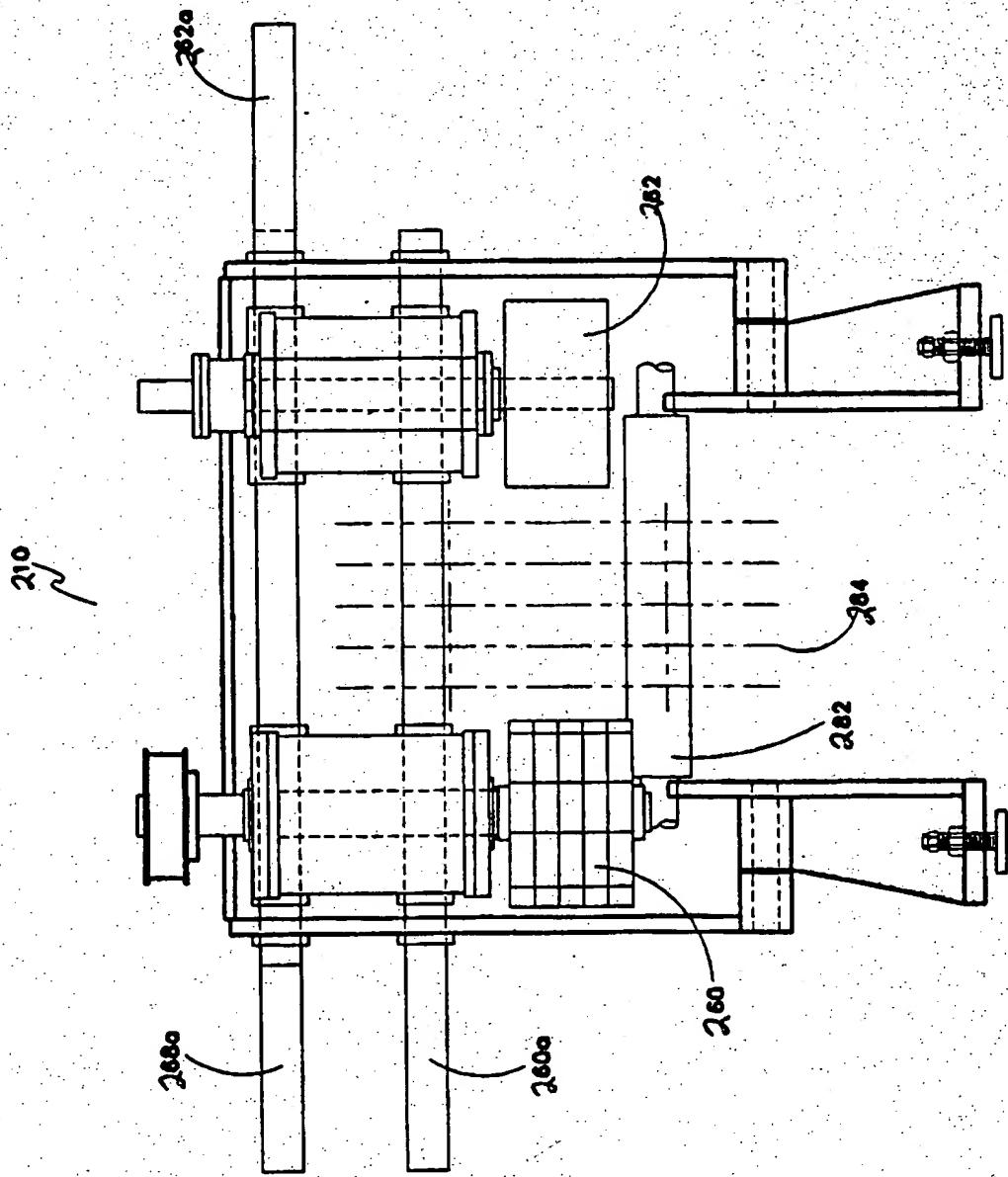
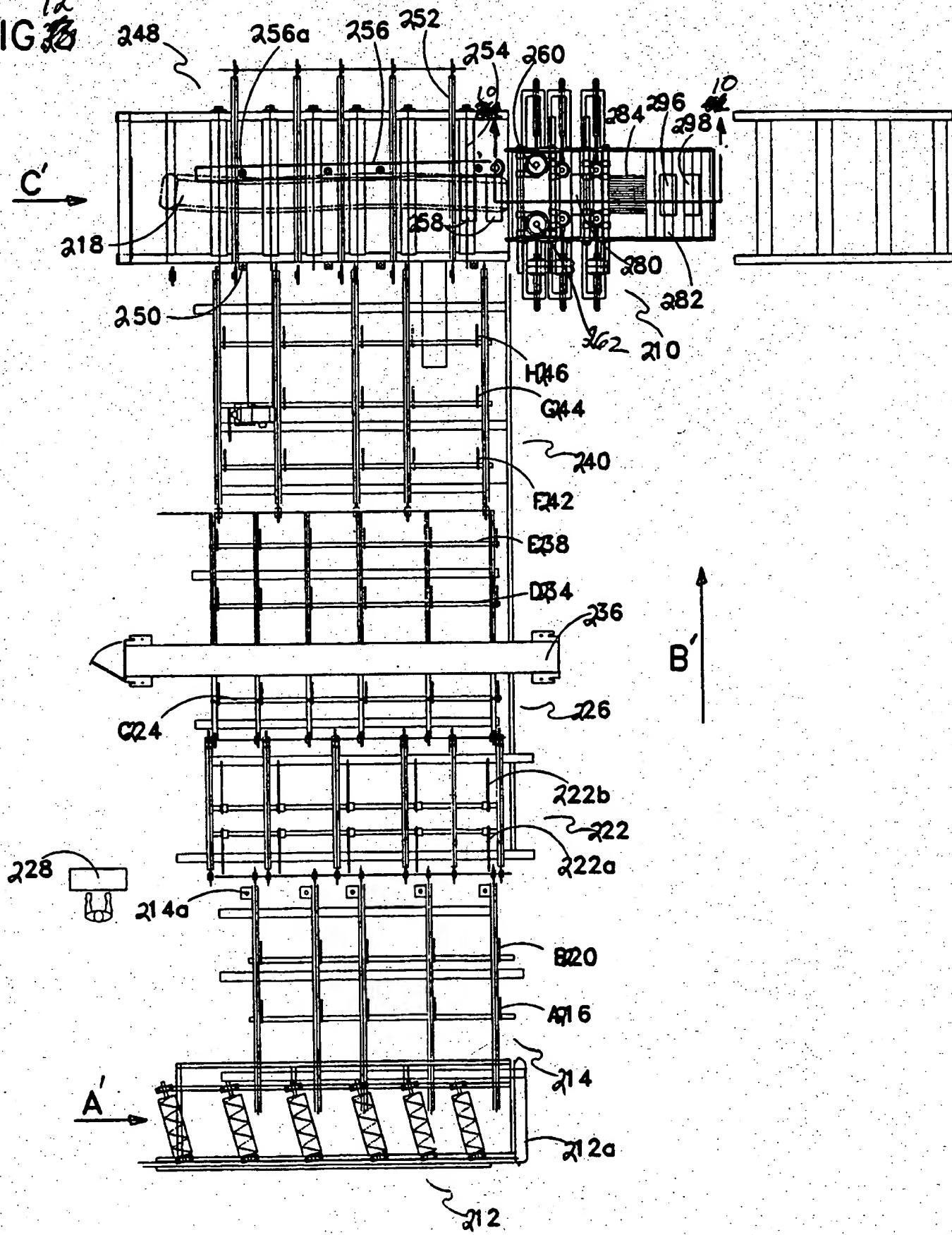
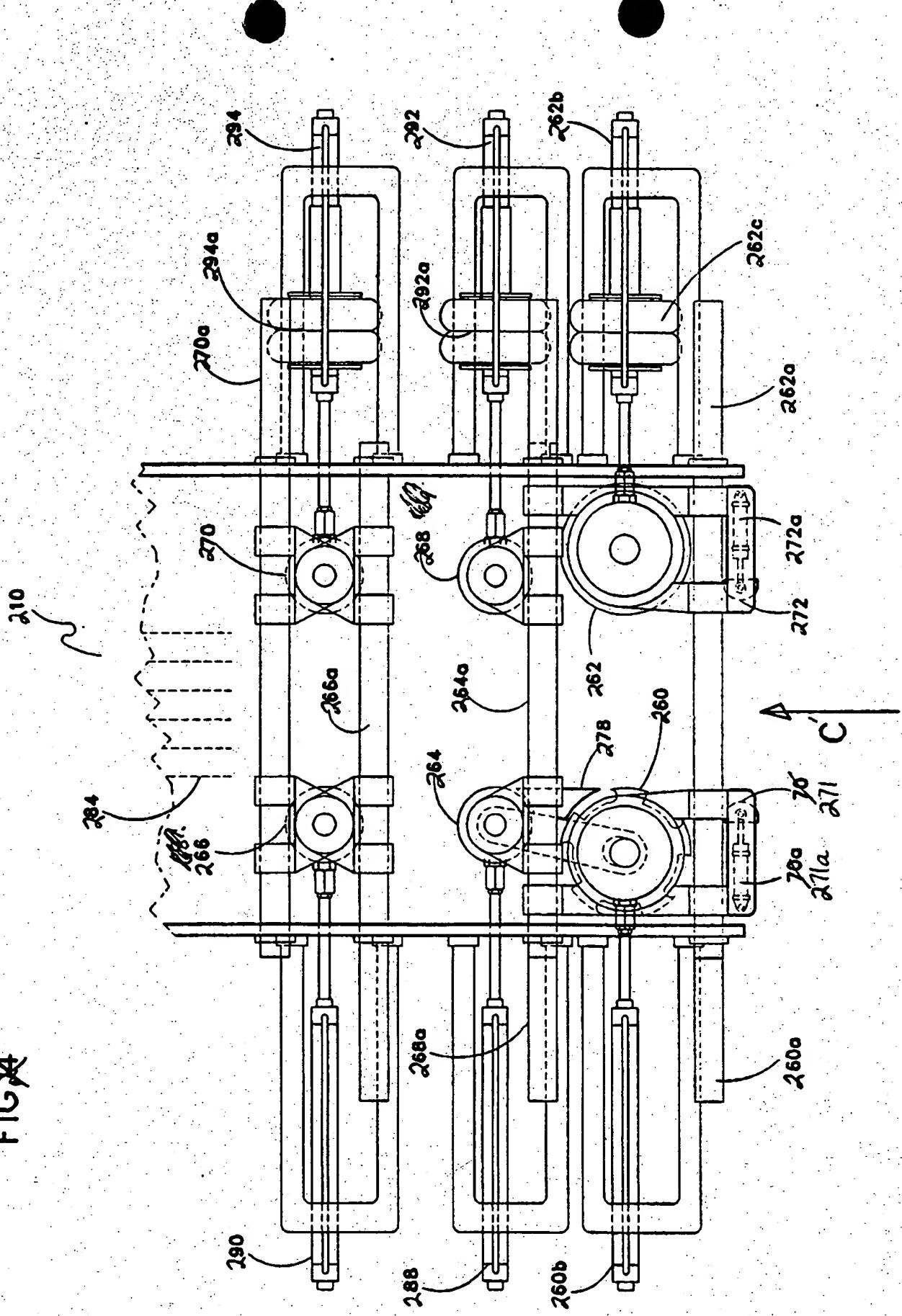
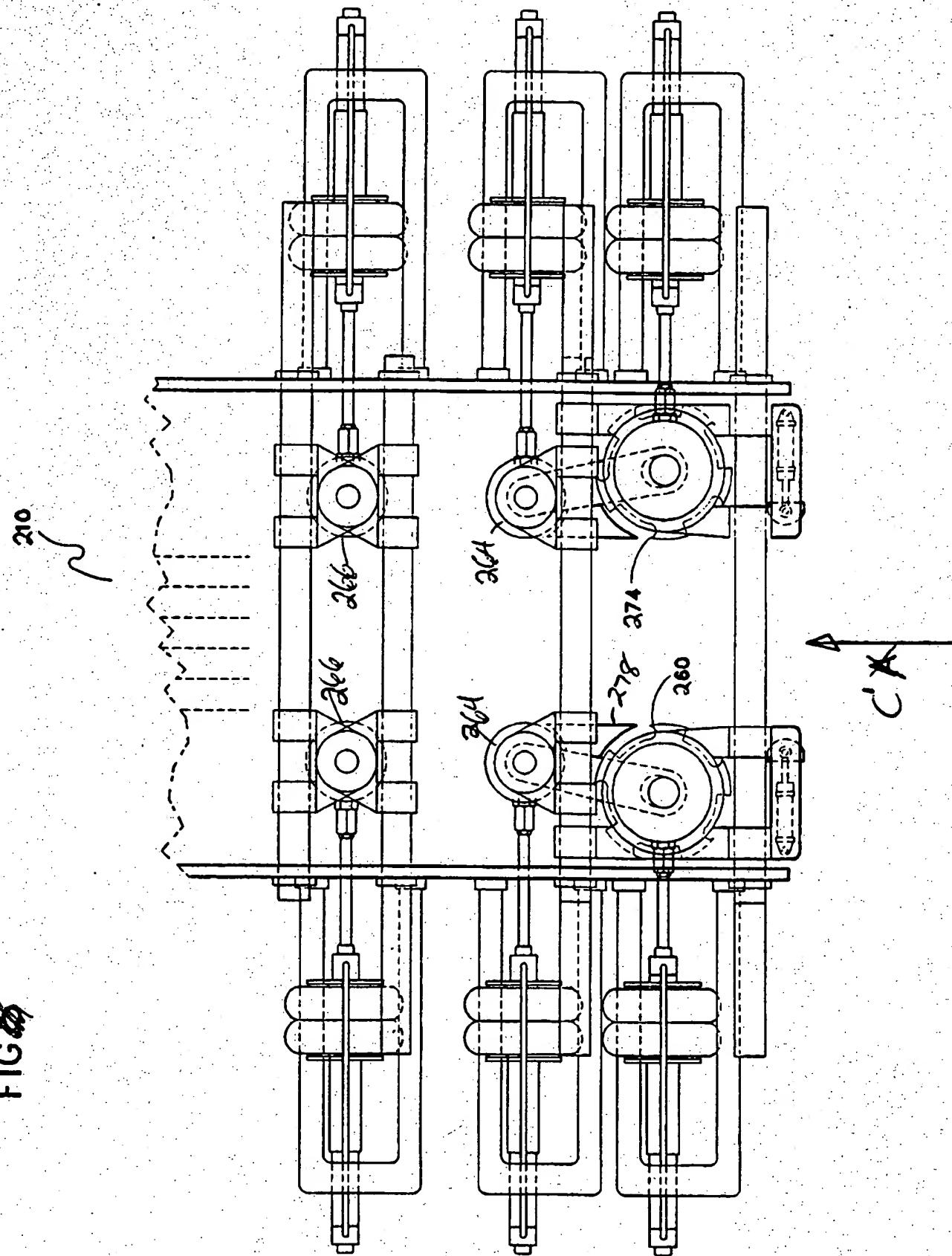


FIG 12



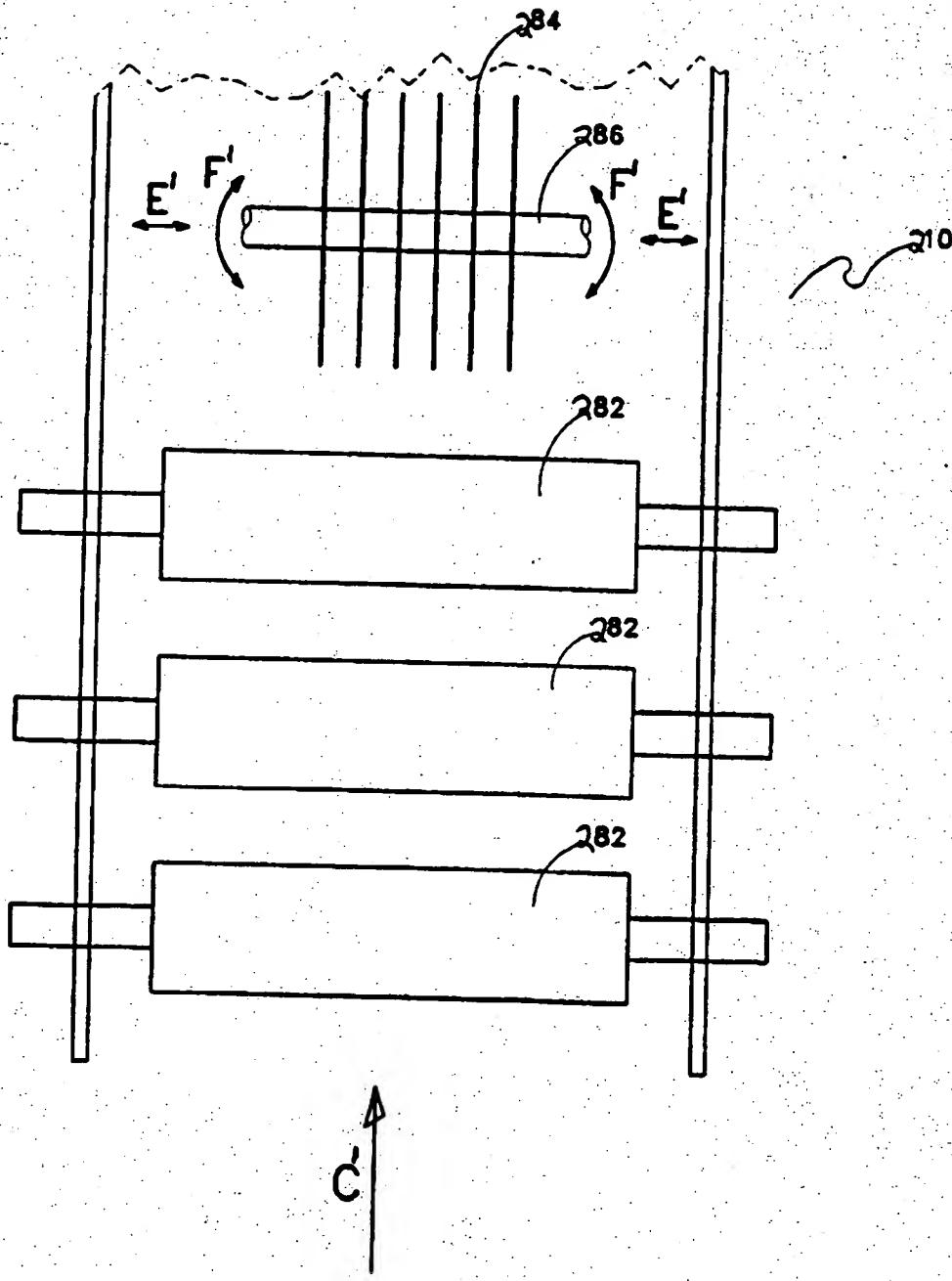


13
FIG. 4



144

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FIG 18

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FIG. 22

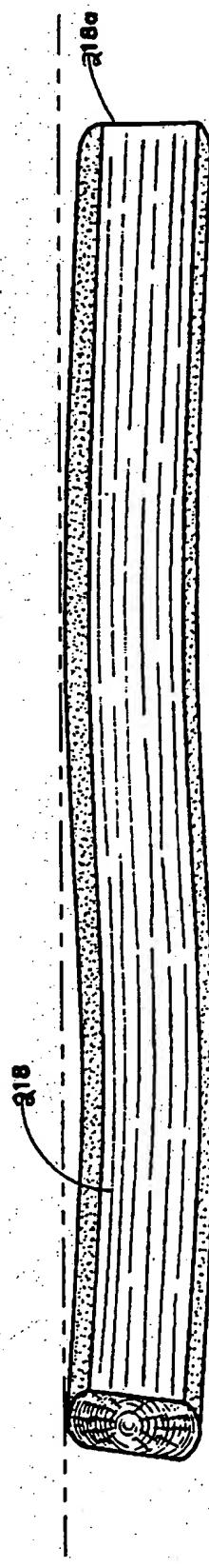
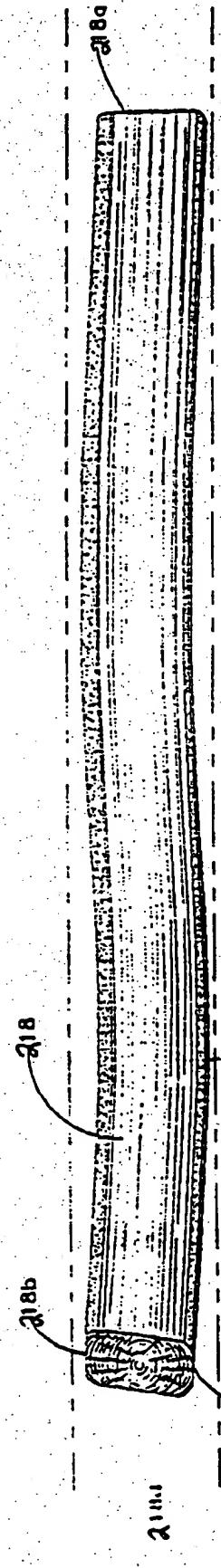


FIG. 22a



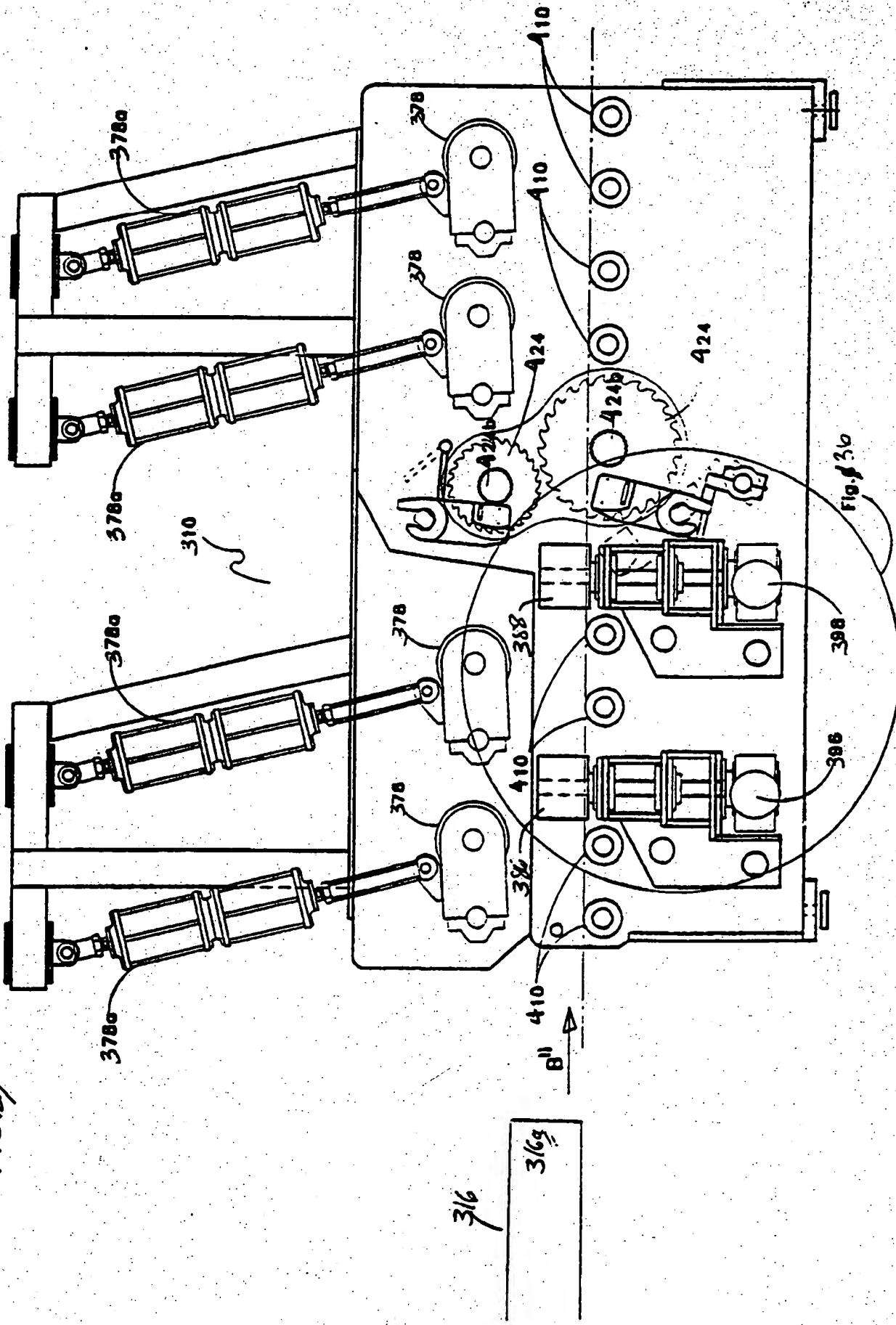
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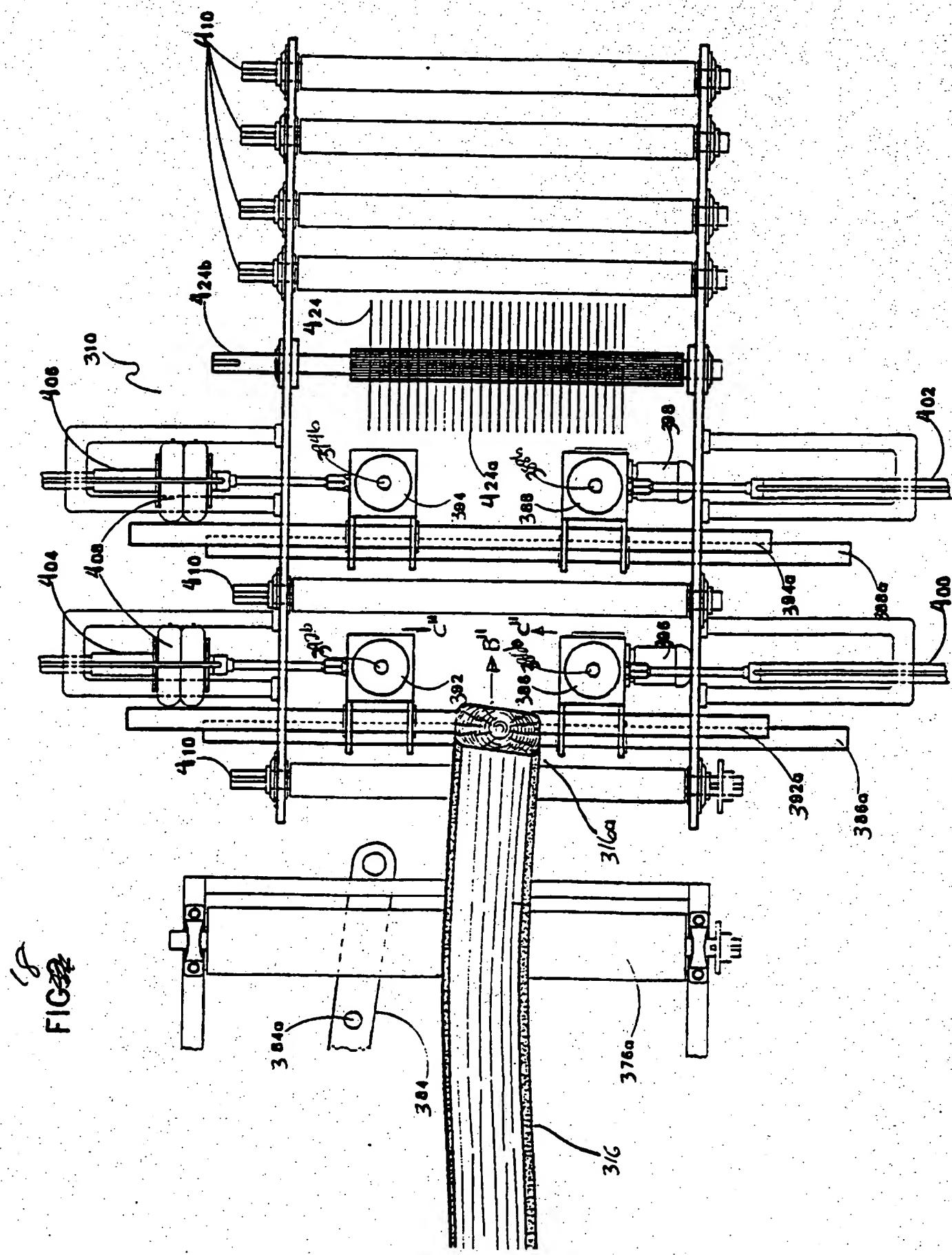
03-21-97 12:21 BISHOP COMPANY

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8/822947

FIG 17





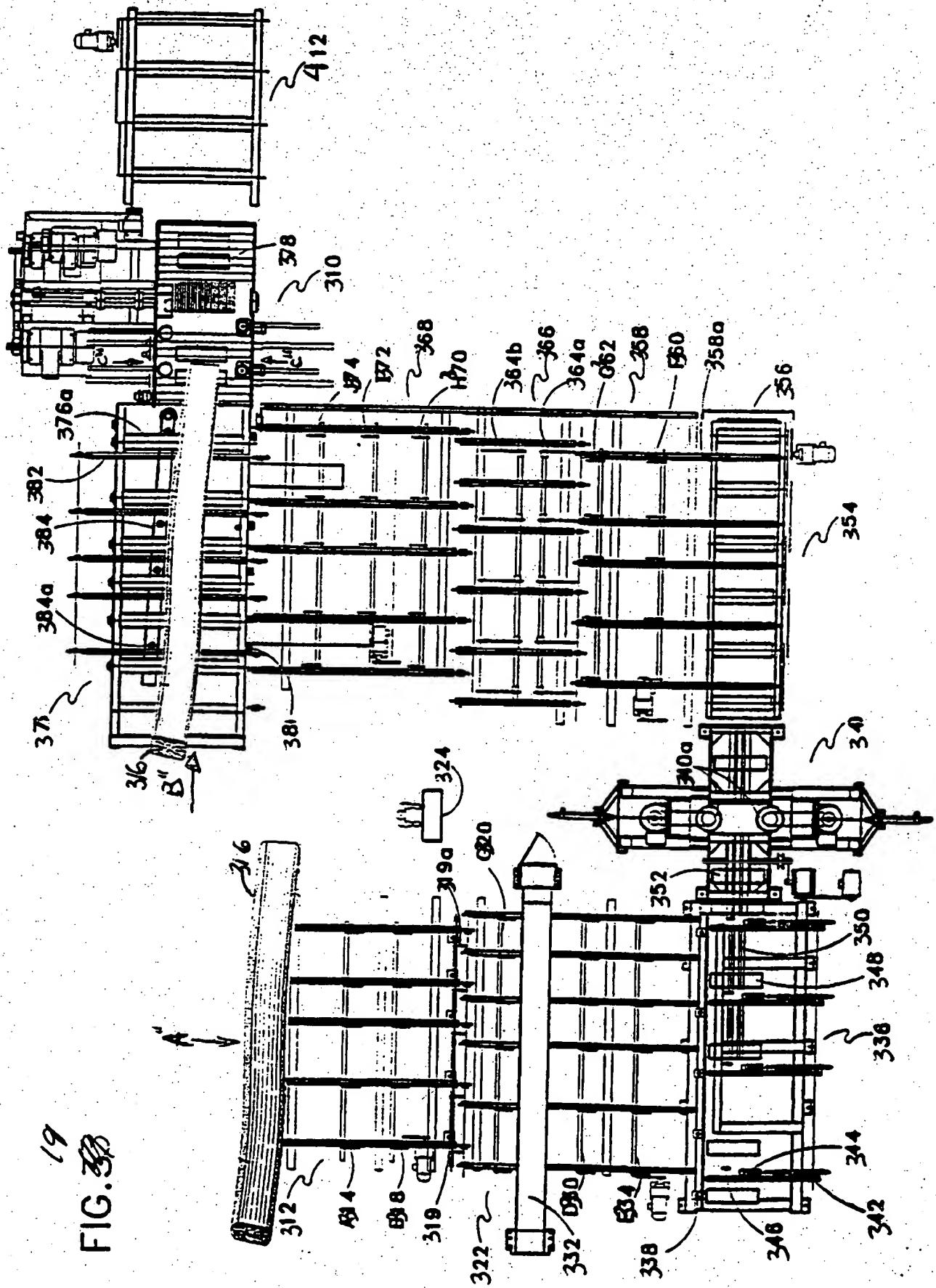
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12:12-22 BISHOP COMPANY 110-8004 B82 35387 21-21-033-003-21-97 22-113

19
FIG. 303



80/822947

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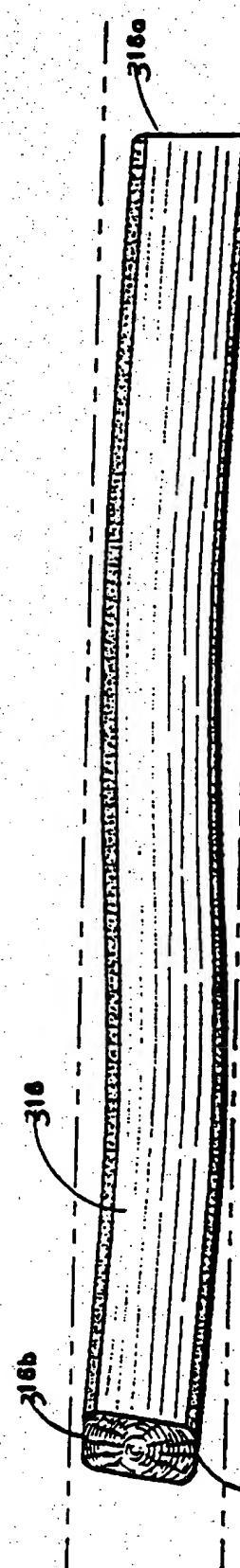
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03-21-94 12:45:20

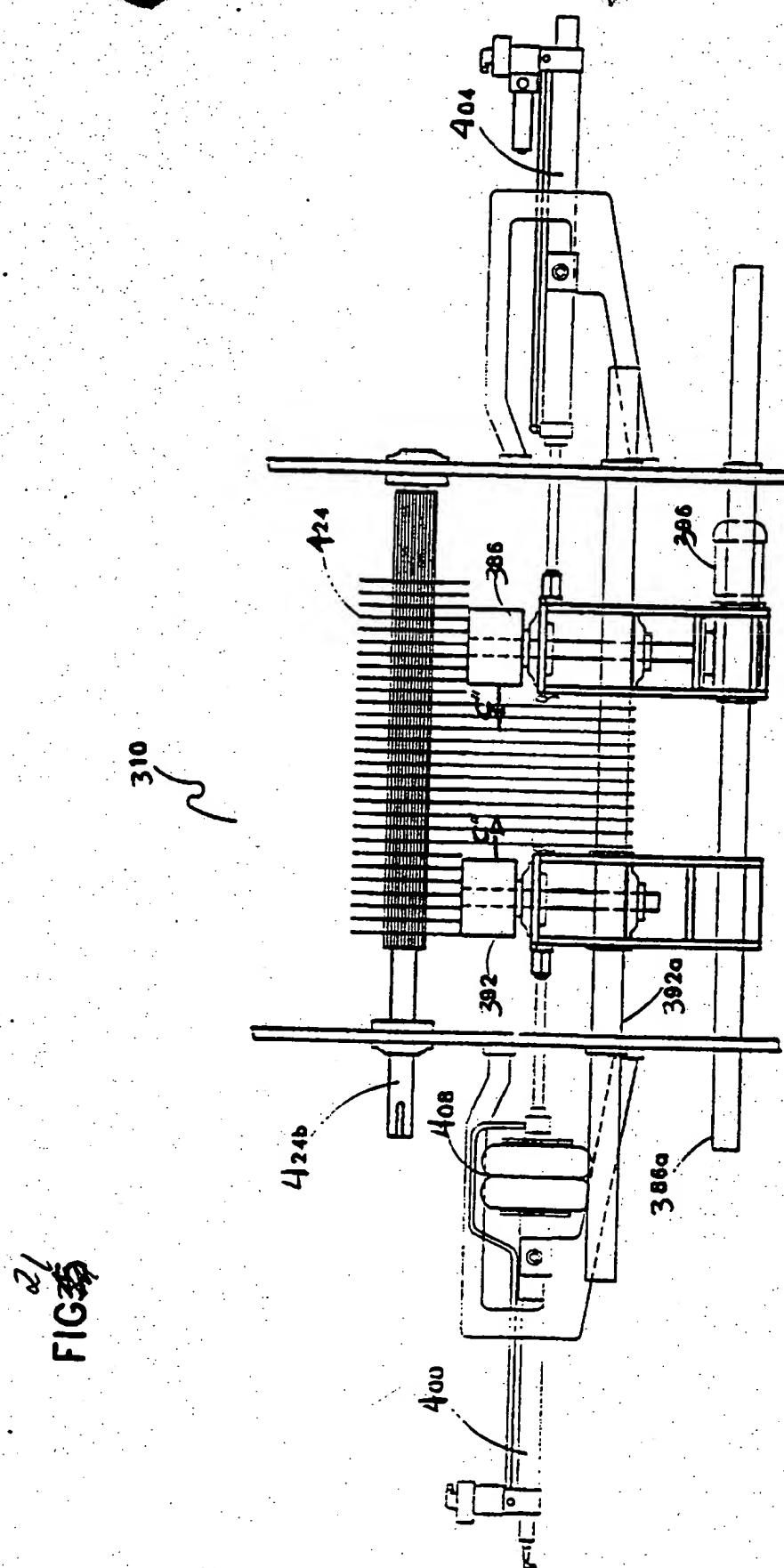
FIG 20



FIG 20a



316a



21
FIG. 21

